

Robotics Service Bus - Bug #608

Default configuration is unusable without user configuration

10/05/2011 09:50 PM - J. Moringen

Status:	Resolved	Start date:	10/05/2011
Priority:	High	Due date:	
Assignee:	J. Moringen	% Done:	100%
Category:	C++	Estimated time:	0.00 hour
Target version:	0.5		

Description

When no user configuration (config file, environment variables) is present, the default configuration only contains the Spread transport. It is not possible to programmatically use other transports like this:

```
ParticipantConfig::Transport inprocess = config.getTransport("inprocess");
inprocess.setEnabled(local);
config.addTransport(inprocess);
```

In the above code, config.getTransport("inprocess") throws an exception unless the inprocess transport has been mentioned in some user configuration.

Associated revisions

Revision 6496340c - 10/06/2011 01:40 PM - J. Moringen

Some preparatory changes in src/rsb/ParticipantConfig.{h,cpp}

refs #608

- src/rsb/ParticipantConfig.{h,cpp}: added enabled parameter to ParticipantConfig::Transport constructor; allow retrieving a mutable reference to ParticipantConfig::eventReceivingStrategy; use rsc::runtime::Printable for printing of ParticipantConfig

Revision 2915694d - 10/06/2011 01:57 PM - J. Moringen

Fixed default transport selection in src/rsb/Factory.cpp

fixes #608

- src/rsb/Factory.cpp: when constructing the default participant configuration, add (disabled) entries for all registered transports in the connector factories instead of relying on the presence of user configuration; enable the spread

Revision 841fb0c8 - 10/06/2011 06:48 PM - J. Moringen

Added getConnectorInfos in src/rsb/transport/Factory.h

refs #608

- src/rsb/transport/Factory.h: added getConnectorInfos method to ConnectorFactory class

History

#1 - 10/06/2011 11:01 AM - J. Moringen

- Status changed from New to In Progress

#2 - 10/06/2011 02:00 PM - J. Moringen

- Status changed from *In Progress* to *Resolved*
- % Done changed from 0 to 100

Applied in changeset r2803.